ABSTRACT OF THE DISCLOSURE

A method and a system for controlling a first robot and at least one other robot is provided. The at least one other robot is calibrated relative to the first robot by the determination of at least one coordinate transformation of the first robot relative to at least one other robot. The at least one transformation is stored in a control device of the other robot. Also, the first robot is calibrated relative to the other robot by the determination of at least one independent coordinate transformation and at least one independent transformation is stored in a control device of the first robot.